THIN FILM PZT PIEZO MEMS FOR MICRO-ROBOTIC ANGULAR RATE SENSING AND ROTARY ACTUATION

Gabriel Smith, Ryan Rudy, Don DeVoe, Sarah Bedair, William Nothwang, Jeffrey Pulskamp, Luz Sanchez, Rob Proie, Vishnu Ganesan, Joe Conroy, and Ron Polcawich

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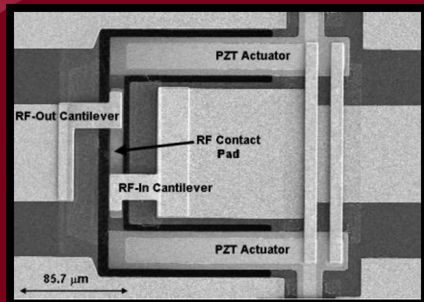
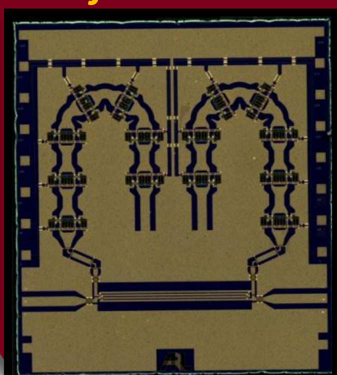
PiezoMEMS Technology

RF MEMS

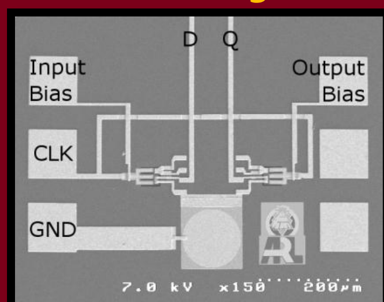
Switches



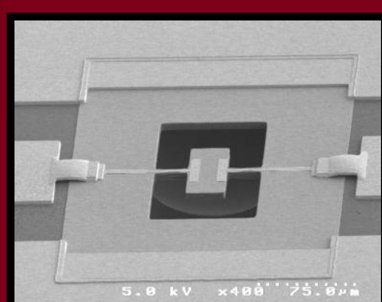
MEMS Phase Shifters



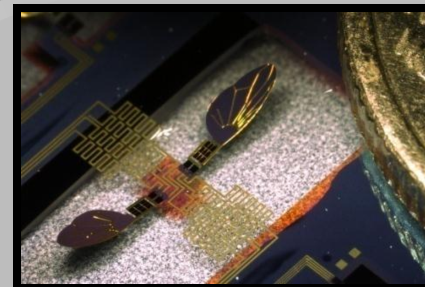
Mechanical Logic



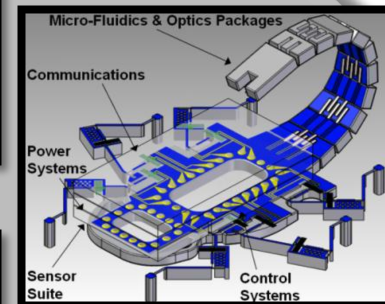
Resonators, Filters, & Transformers



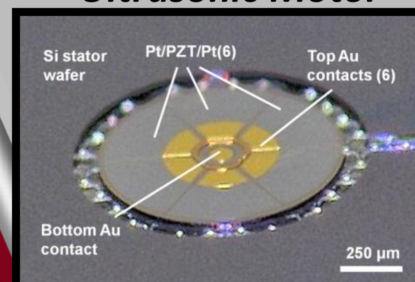
Micro-flight



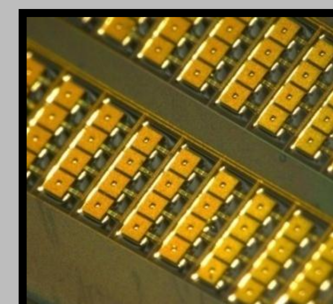
Terrestrial



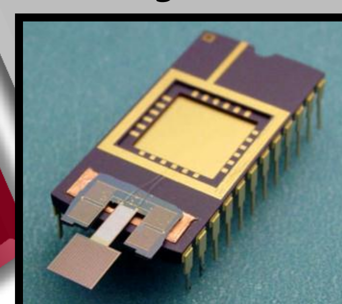
Ultrasonic Motor



Bio-Inspired Adhesives



Piezoelectric Energy Harvesting



MM-SCALE ROBOTICS

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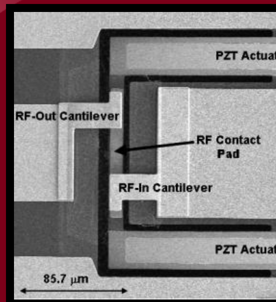
PiezoMEMS Technology

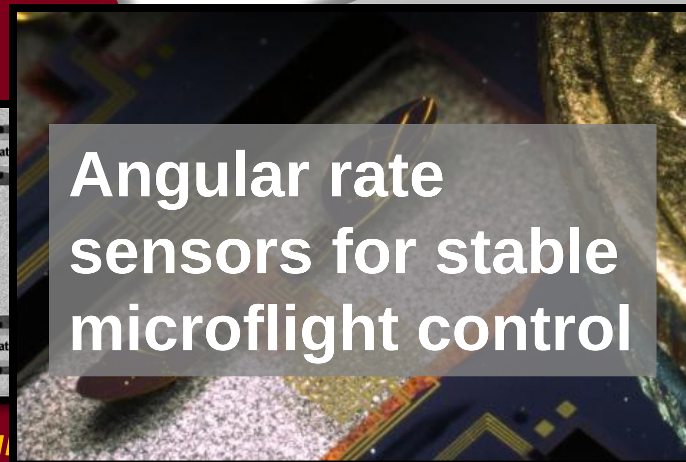
ARL

RF MEMS

Switches



Micro-flight



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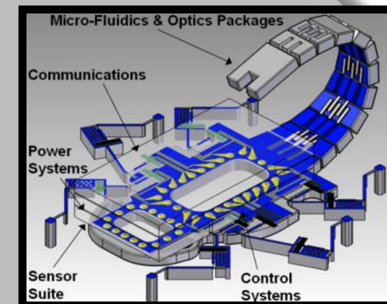
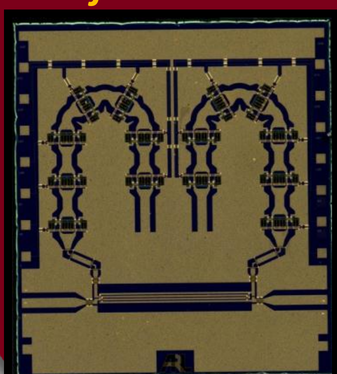
Terrestrial

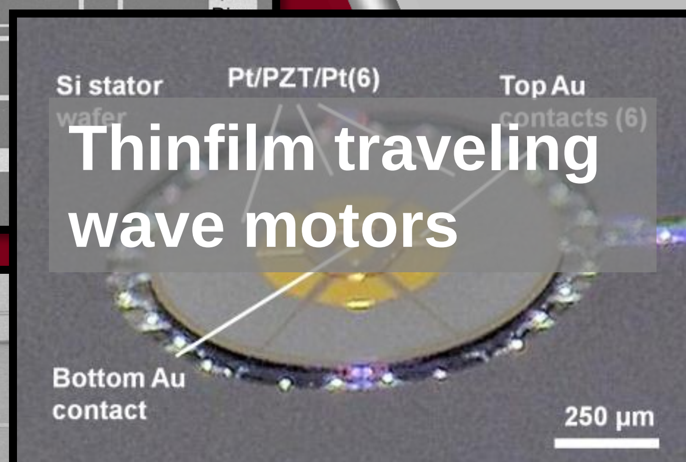


MEMS Phase Shifters

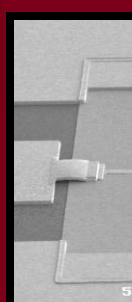


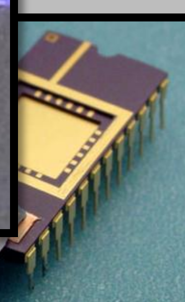
Mecha

Bio-Inspired Adhesives



ic Energy





MM-SCALE ROBOTICS

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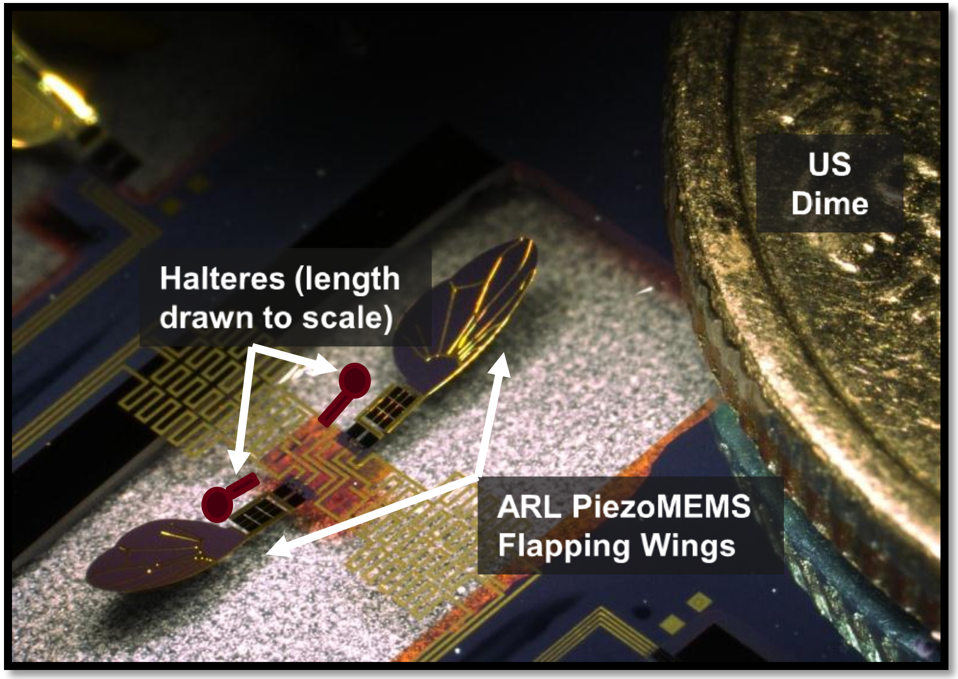
Angular Rate Sensing for mm-scale Robots

Fly Video: M. Dickinson Caltech



Angular rate sensing on 1-30 mg platform

- 2 orders smaller than packaged state of the art gyroscope.
- Integrated biomimetic PZT actuator/sensor approach.
- Haltere-like sensor

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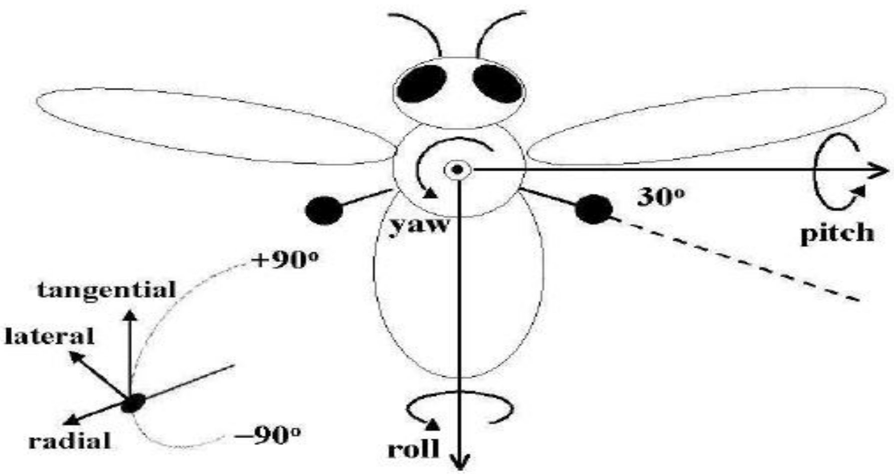
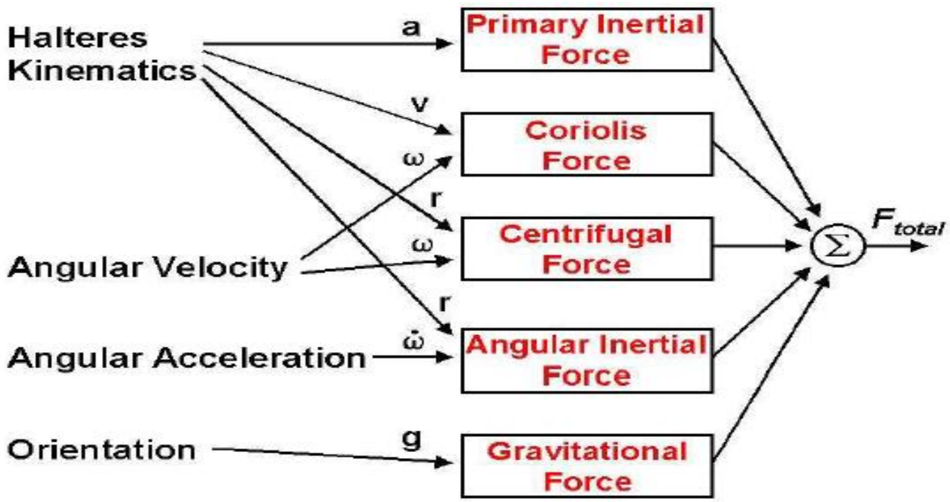
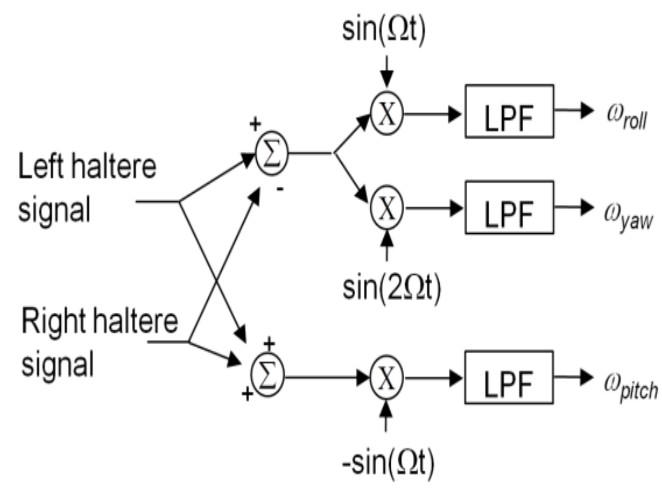
Haltere Mechanics





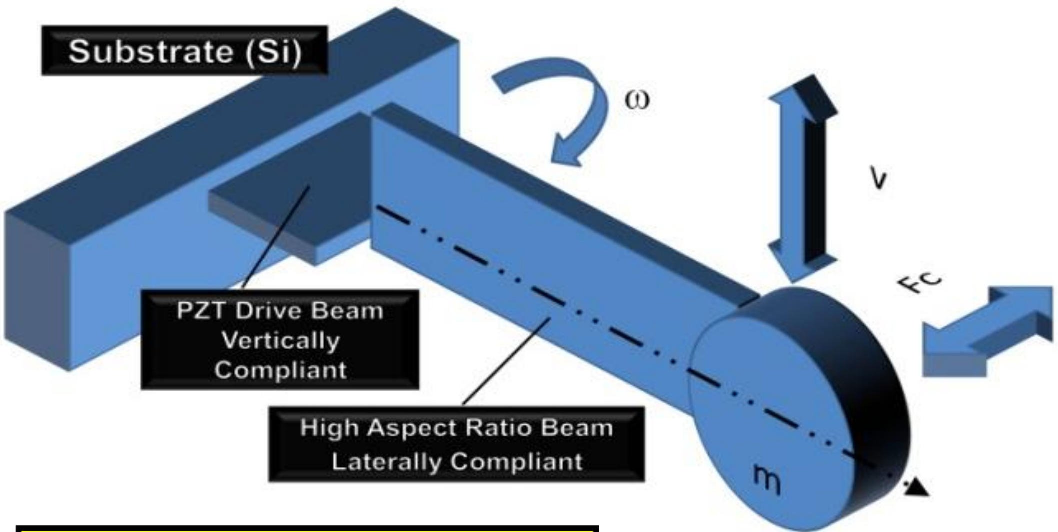


Equation of Motion for macro haltere by Wu et al.

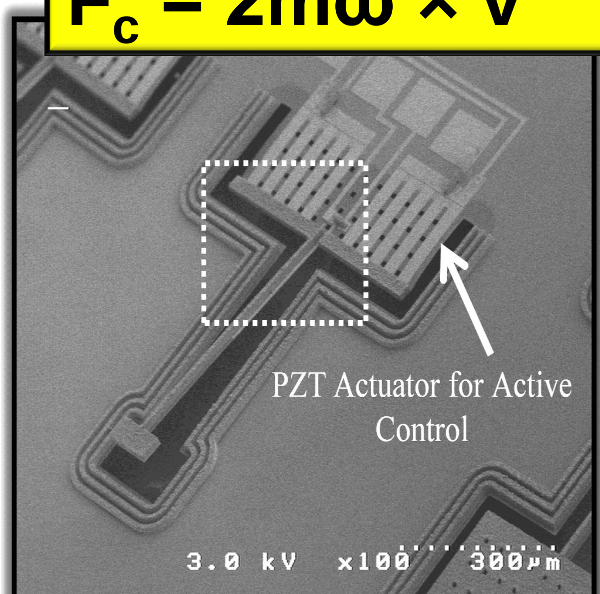
$$
\begin{aligned}
&\ddot{\theta} + 2\zeta\omega_n\dot{\theta} + \omega_n^2\theta = \dot{\Omega}_3\sin(\gamma) - \dot{\Omega}_1\cos(\gamma) - \dot{\gamma}^2\cos(\theta)\sin(\theta) \\
&+ 2\dot{\gamma}[(\Omega_3\cos(\gamma) + \Omega_1\sin(\gamma))\cos^2(\theta) \quad - \Omega_2\cos(\theta)\sin(\theta)] \\
&+ (\Omega_3^2\cos^2(\gamma) + \Omega_1^2\sin^2(\gamma) \; - \Omega_2^2)\cos(\theta)\sin(\theta) \\
&+ (\Omega_2\Omega_3\cos(\gamma) + \Omega_1\Omega_2\sin(\gamma))\cos(2\theta) \; + 2\Omega_1\Omega_3\cos(\theta)\sin(\theta)\cos(\gamma)\sin(\gamma)
\end{aligned}
$$

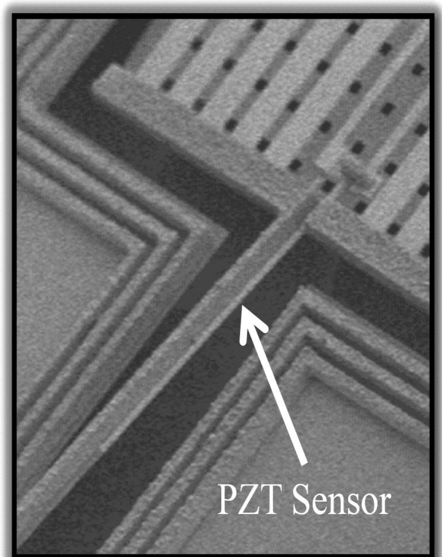
Wu, W. C.; Schenato, L.; Wood, R. J.; Fearing, R. S. Biomimetic Sensor Suite for Flight Control of a Micromechanical Flying Insect: Design and Experimental Results. ***IEEE Int. Conf. on Robotics and Automation***, **Taipei, Taiwan, May 2003.**

Orthogonal Actuation and Sensing



$$F_c = 2m\omega \times v$$



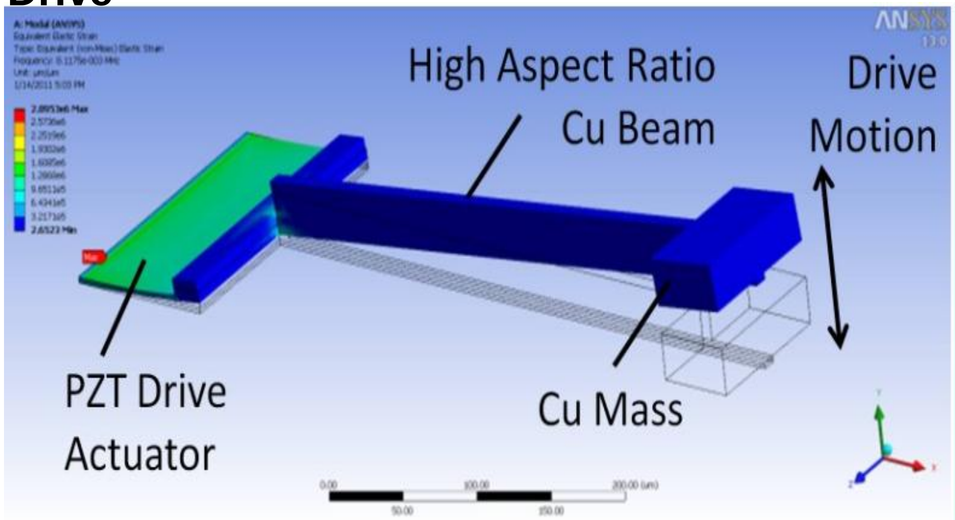


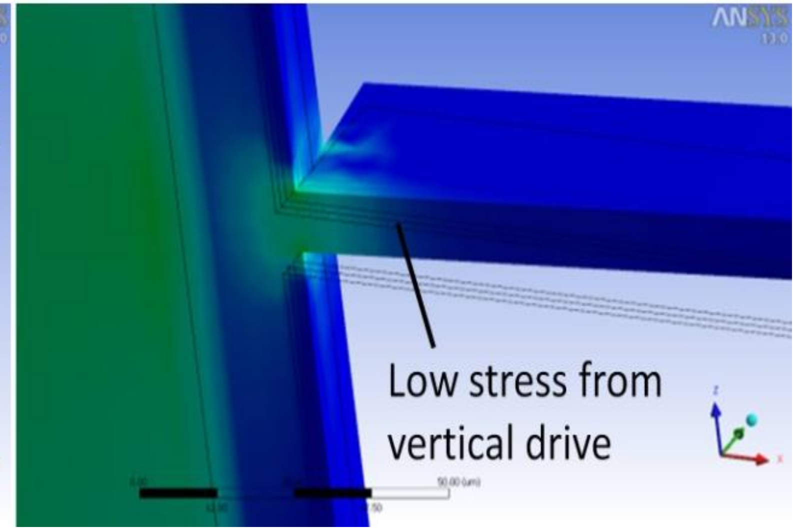
Fundamental Challenges:

- **Body Vibrations**
  - Raise Frequency of sensor structure above wing beat
- **Complex Forces on 3 axes**
  - Oscillate the Haltere to extract the ang. rate components
- **Axis Isolation**
  - Couple the 2 Haltere electrical signals
  - Decouple the rate information for 3 axis
- **Low Q**
  - Trade size, weight, power for sensitivity

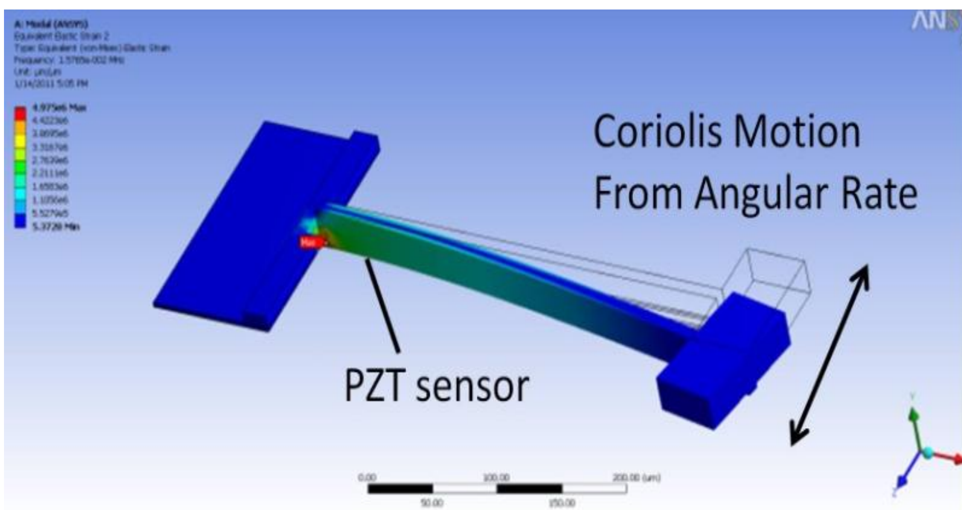
ANSYS Modal Analysis

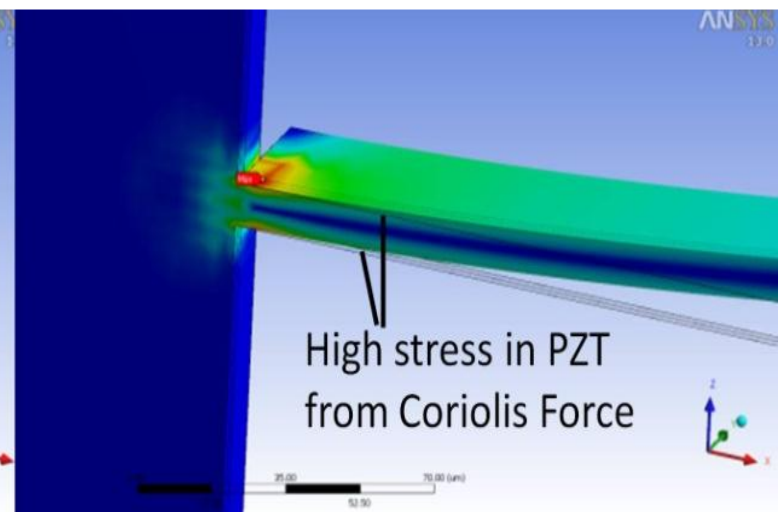
Drive



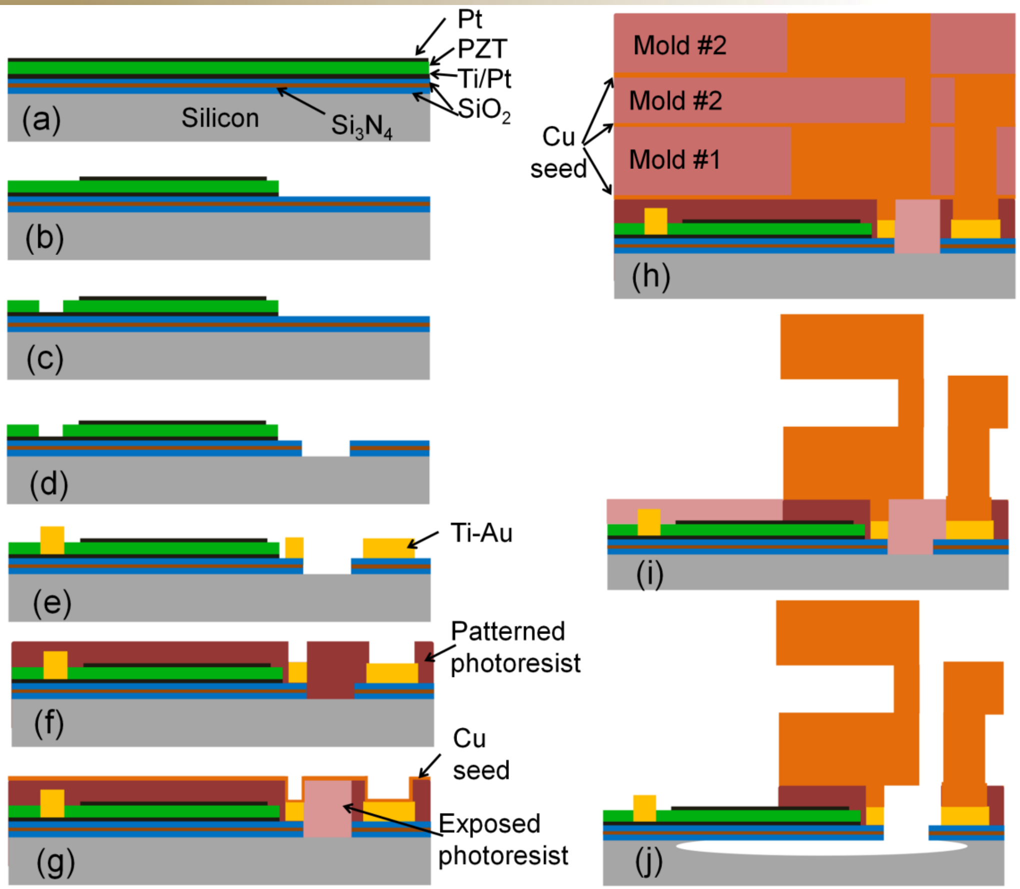


Sense

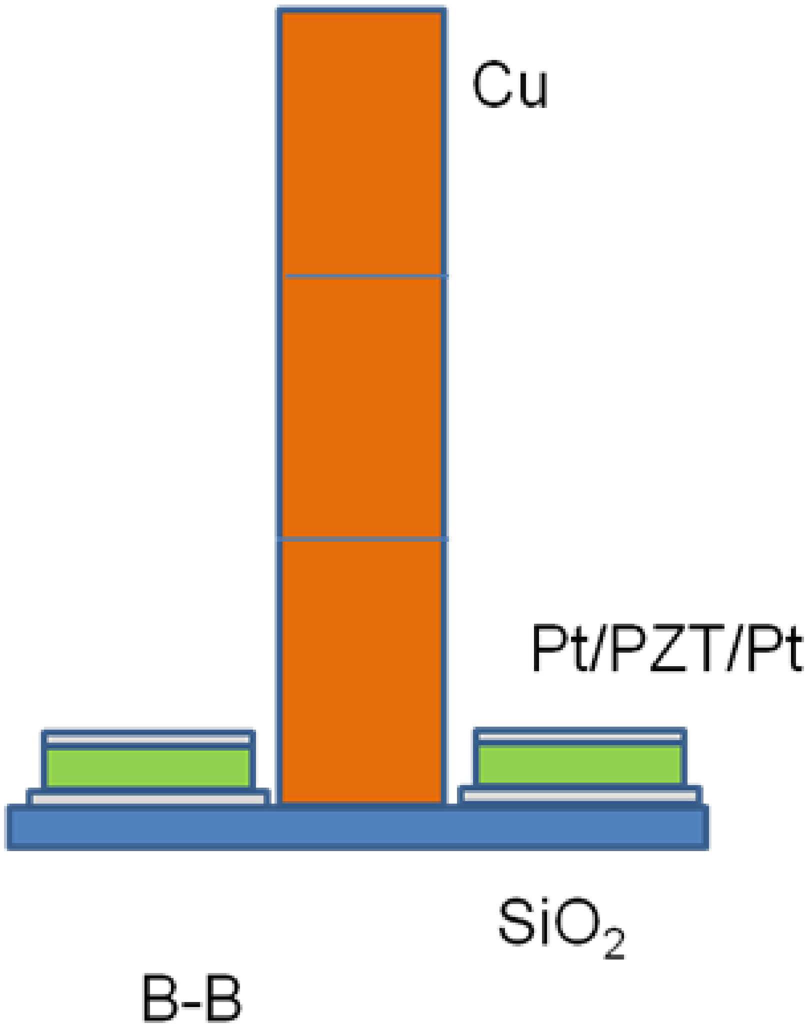




Cu PZT MEMS Fabrication Process



Material	Nominal Thickness
Cu	10-30 µm
Top Pt	1000A
PZT	1 µm
Bottom Pt	1000A
SiO_2	2 µm



Collaboration with Chris Meyer (ARL)

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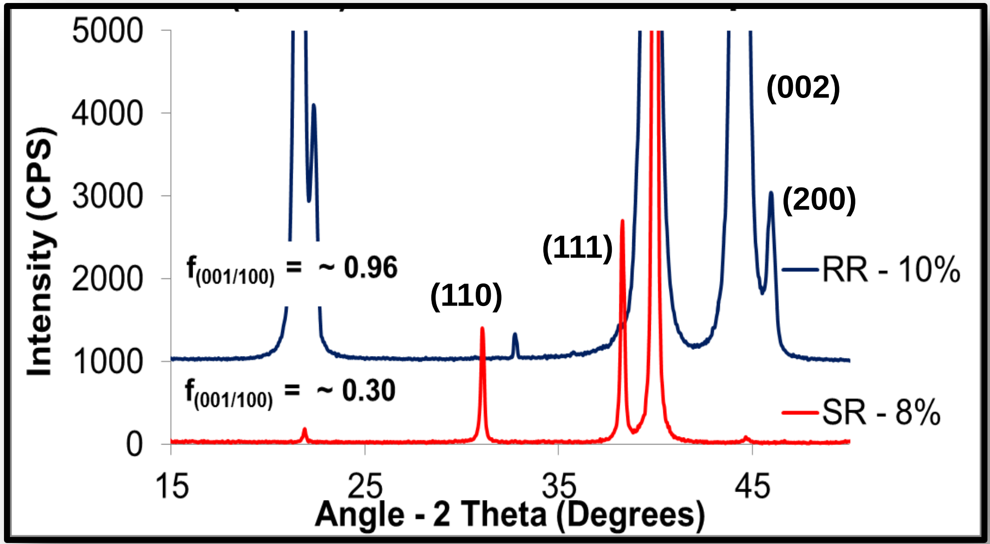
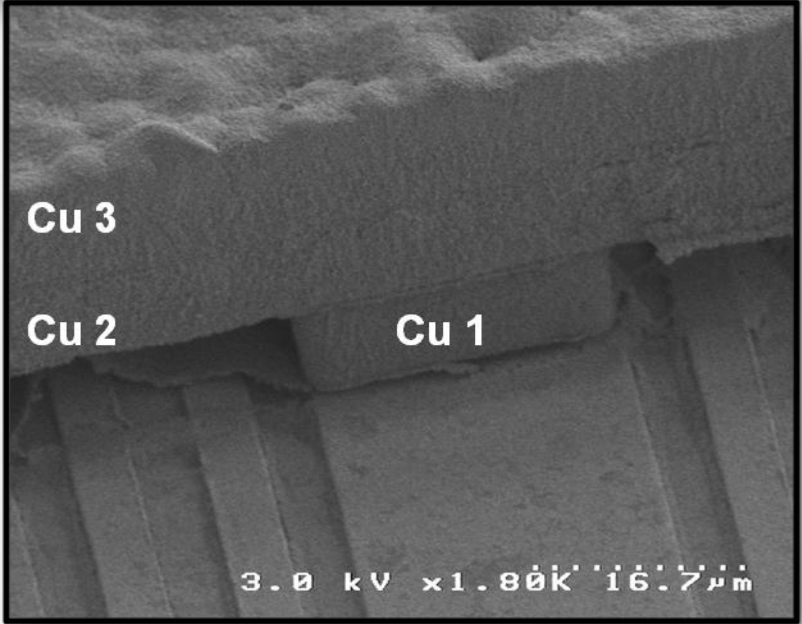
Fabrication Specifics

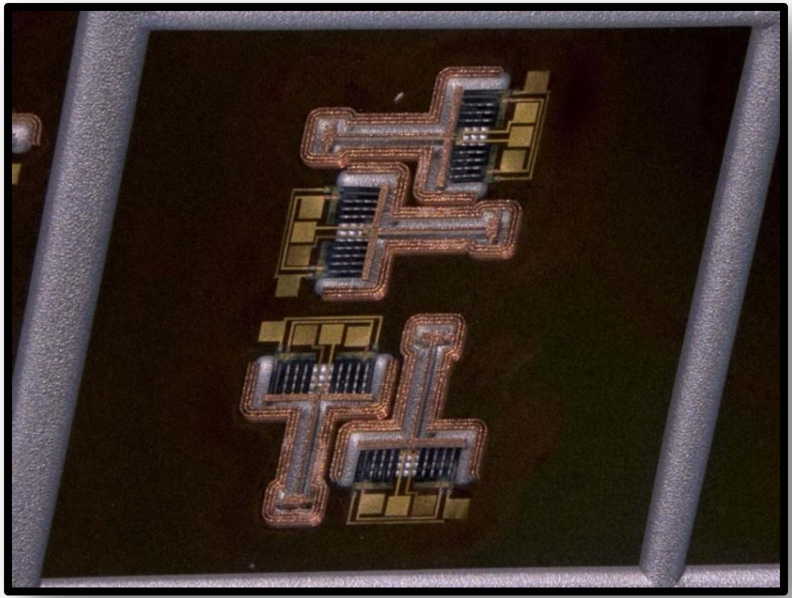
- PZT (52/48) thin films
  - Deposited by chemical solution deposition with 10% Pb excess
  - Pt template (111) with a FWHM of 2 deg
  - (001) PZT with a Lotgering Factor > 0.95
- Pt & PZT Patterning → Ion-mill configured with SIMS endpoint detection
- Multilayer Cu Process → 3 layers
  - Electroplated Cu
  - Photoresist Molds
  - Wet release process for molds
- Final Release
  - Isotropic XeF_2 etch of exposed Si

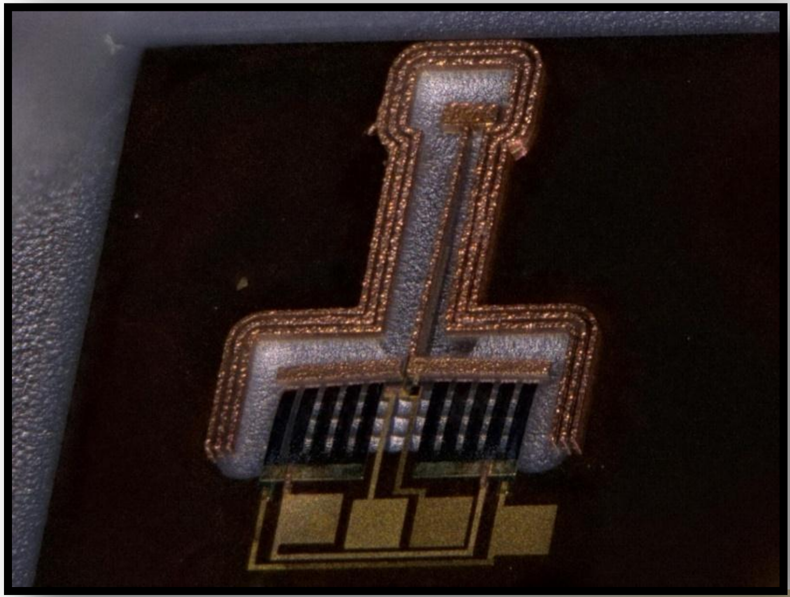




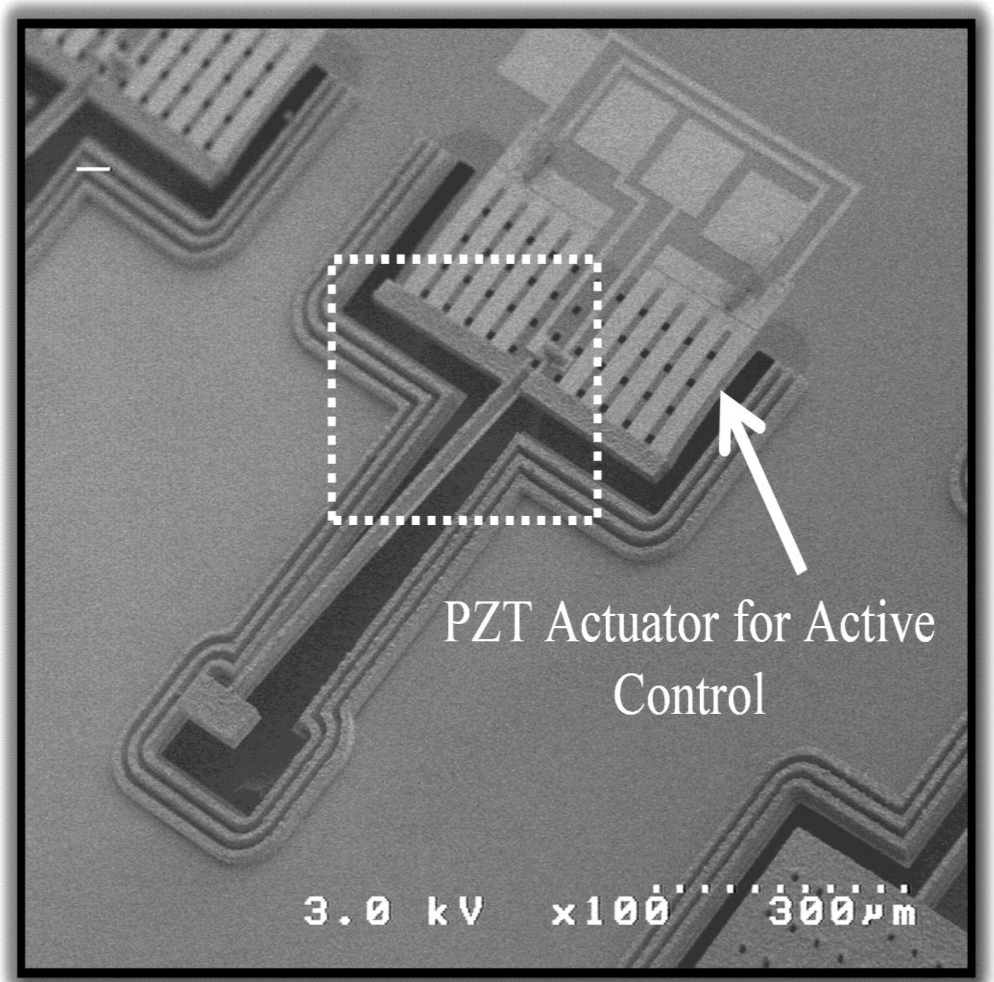
Results: MEMS Fabrication

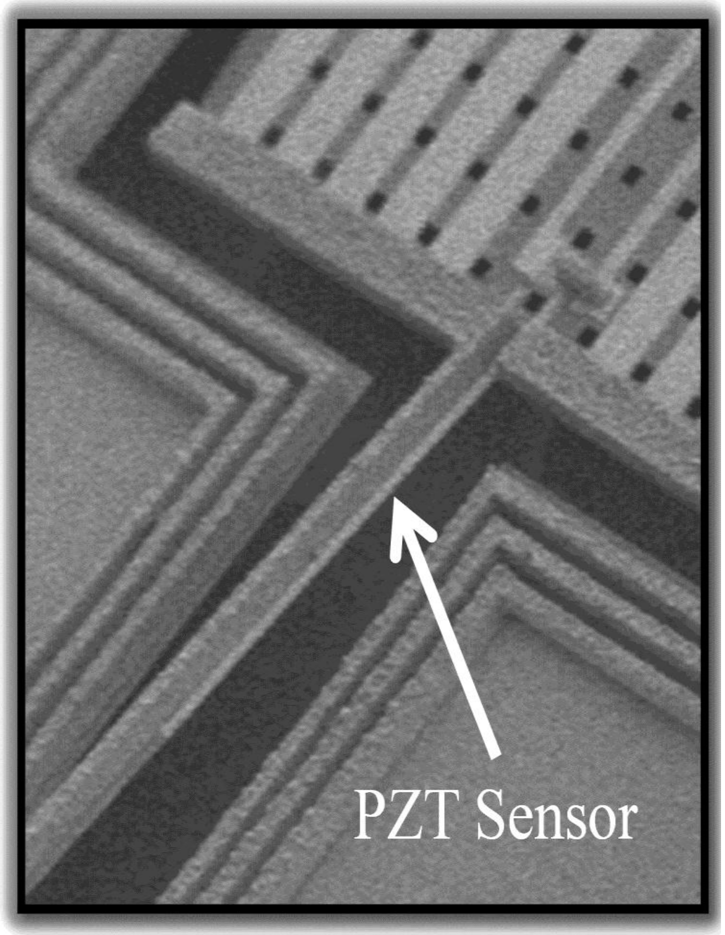
- Length & Size Variances
- Individual Devices
- 2-axis sensing





Actuation and Sensing





SEM of a PZT-based MEMS haltere actuator and sensor

MEMS Device Testing

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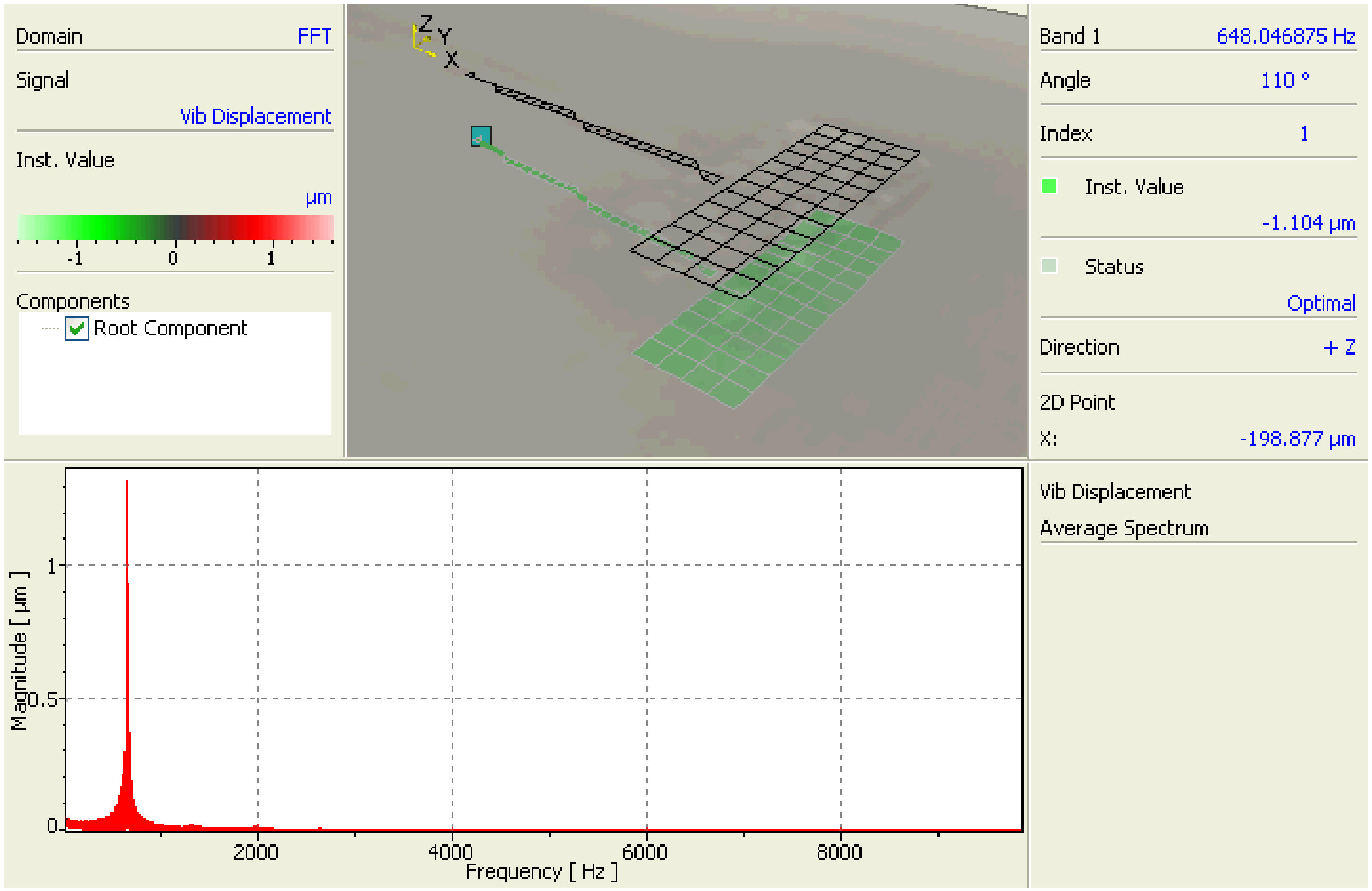
Laser Doppler Vibrometer Testing



LDV Data

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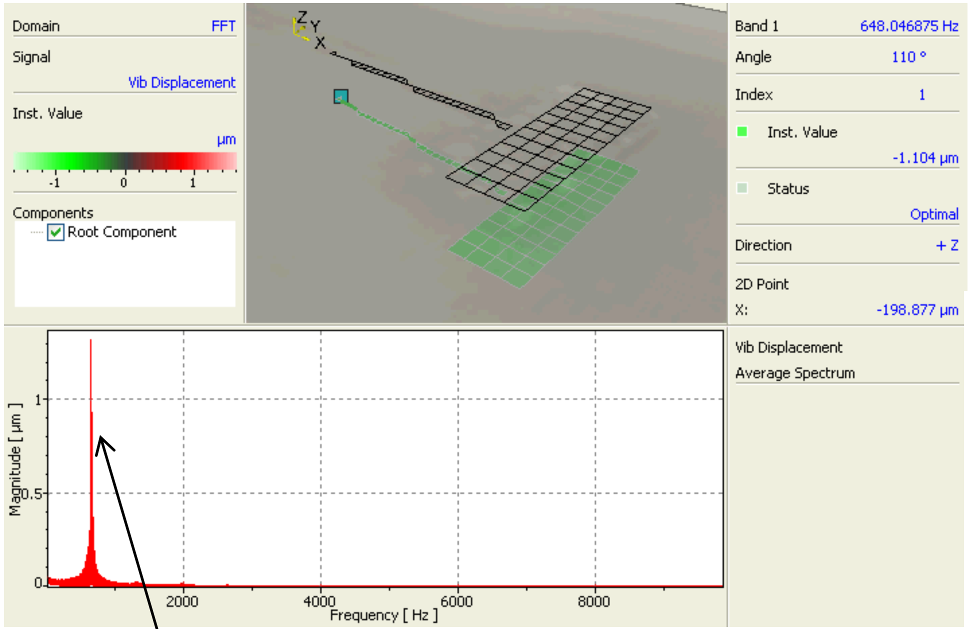
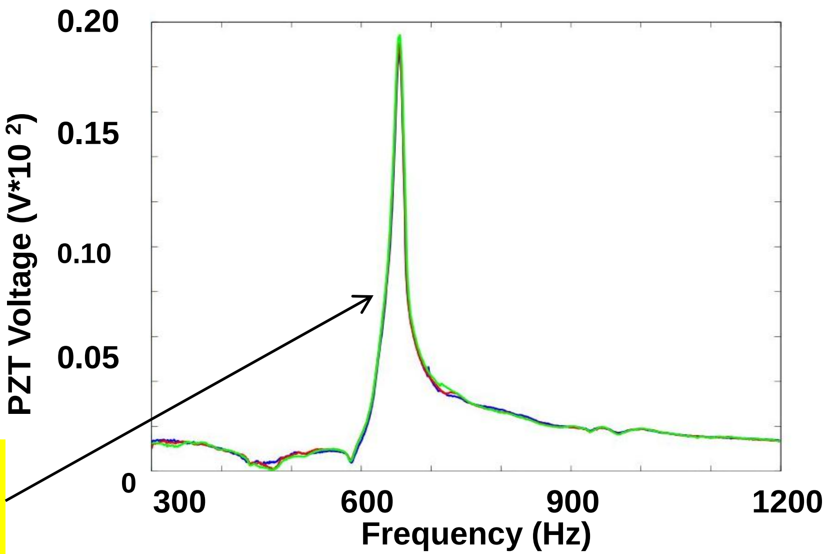
LDV and Shaker Testing

Frequency response of the beams was measured on both Laser Doppler Vibrometer and a shaker table.



LDV Data

Amplified (100x) signal on drive PZT actuator when excited by external shaker



Both show the same fundamental resonance at 648Hz

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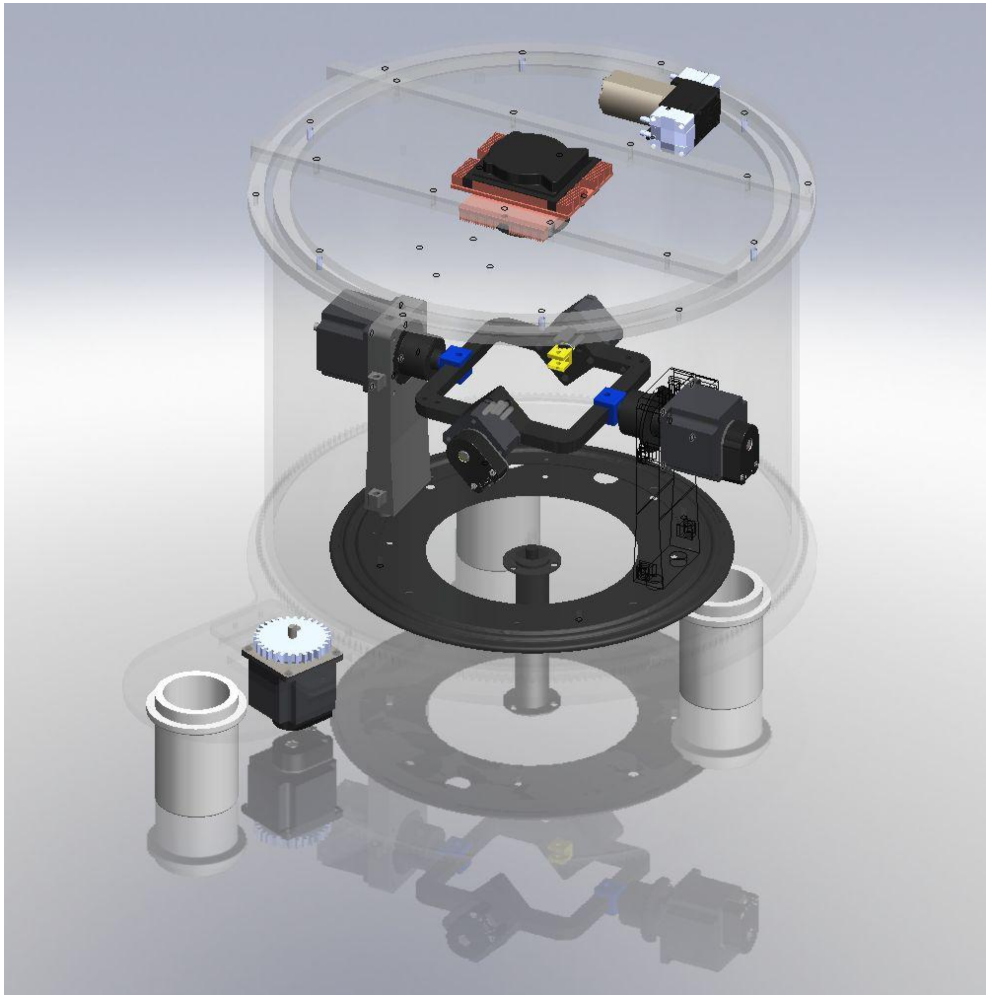
Angular Rate Testing



- 3-Axis angular rate table, design and fabrication by J. Shumaker (ARL -VTD)
- Haltere circuit is sensitive to
  - Drive Motor Noise
  - Slip Rings
  - Unshielded Wiring
- Initial qualitative results indicate that the sensor element detects rotation
- New circuit pending to quantify rate sensitivity.

PiezoMEMS Thinfilm Ultrasonic Traveling Wave Motors

University of Maryland

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Traveling Wave Ultrasonic Motors

Macro Traveling Wave USM Advantages:

- High torque at low speed
- Low power
- No gearing required
- Zero backlash
- Holding torque with zero standby power
- Compact & few moving parts
- Unaffected by electromagnetic interference

– Commercially in DSLR camera auto focus lenses

– Shinsei, K. Uchino, A.V. Carazo et al.

MEMS Thin-Film USM

•Reduced size (<1mm^3)

•Traveling wave style USM previously shown only at >1cm scale

•Flat profile-surface mount

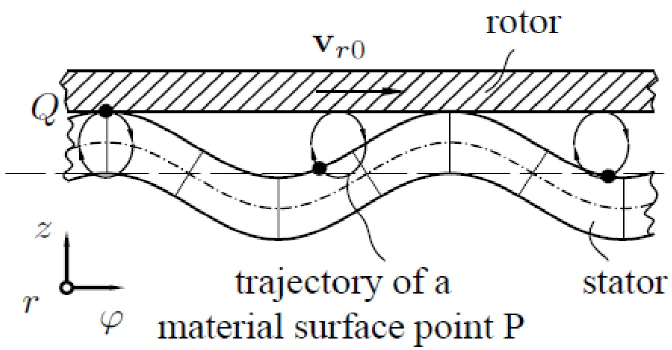
•Low voltage operation (0-10V)

•Wafer level fabrication and packaging

•No assembly required

•Batch production

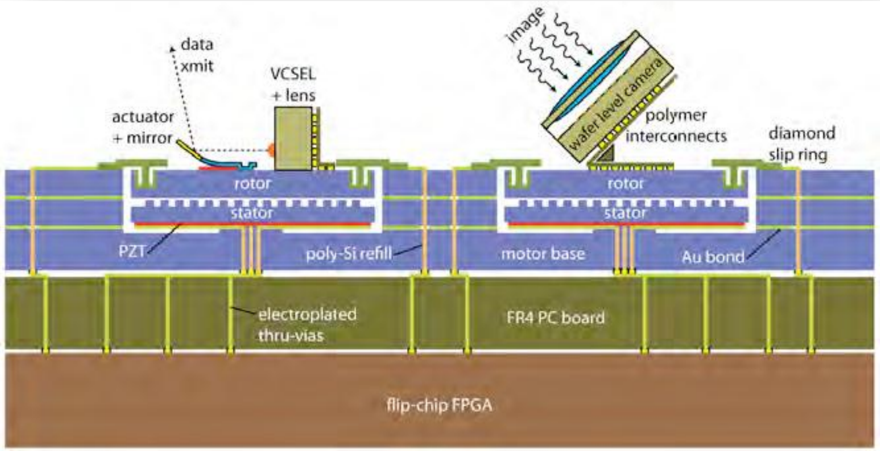
•Lower cost with volume

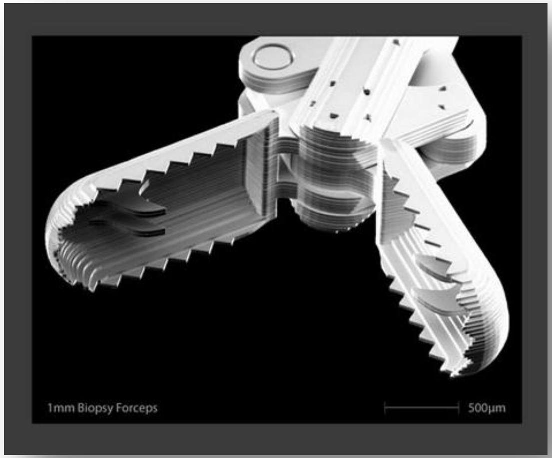


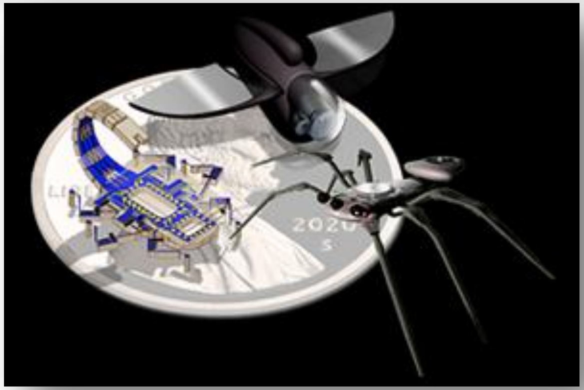
T. Sattel, "Dynamics of Ultrasonic Motors", Doctoral Thesis, Technische Universität Darmstadt, Germany, 2002.

Applications

- Small scale robotics
- Steering directional sensors and optical devices
- Information Tethered Micro Automated Rotating Stages (DARPA)
- Medical MEMS





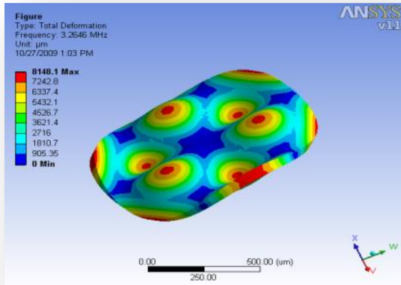


"Microfabrica SEM Image Gallery", *Microfabrica – MICA Freeform,* http://www.microfabrica.com/gallery.html, accessed on 7/22/11

"Micro Autonomous Systems and Technology (MAST)", *Micro Autonomous Systems and Technology (MAST) US Army Research Laboratory,* http://www.arl.army.mil/www/default.cfm?page=332, accessed on 5/26/11

How It Works

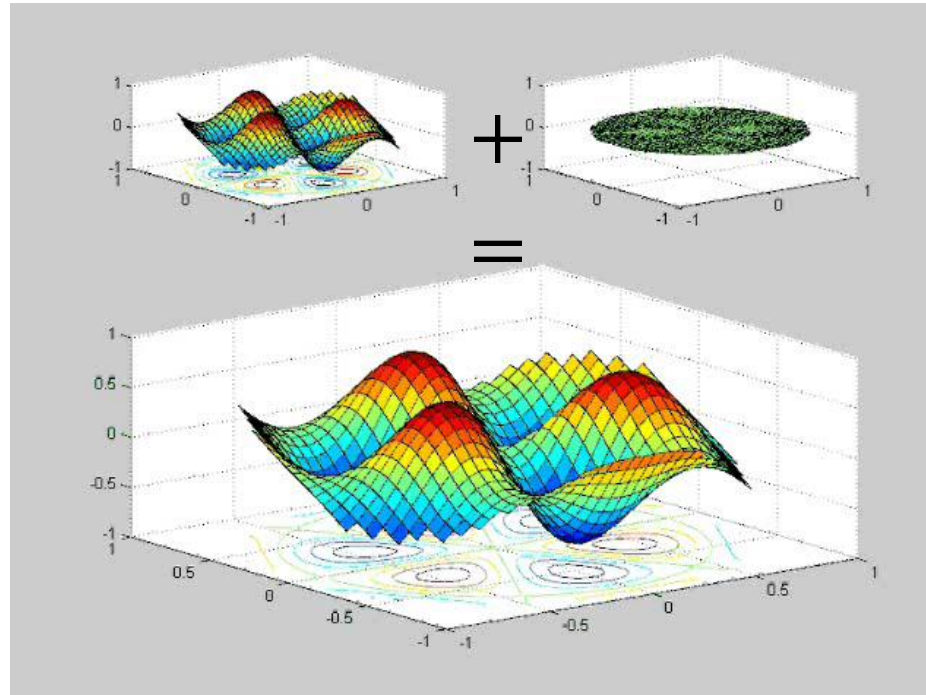
B_{13} mode at 250kHz in 3mm stator



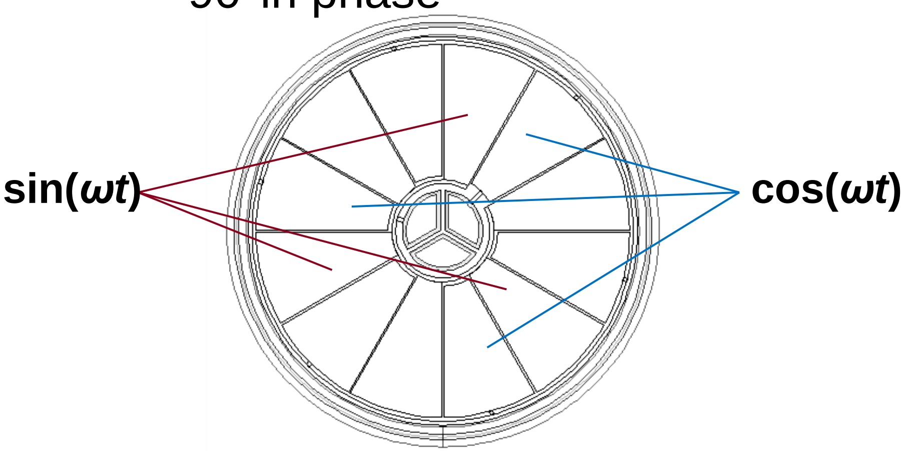
- Combining standing waves apart in space and offset in phase:

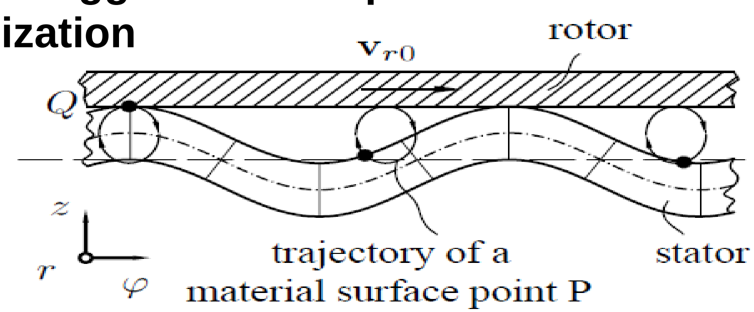
$$\cos(n\theta)\cos(\omega t) + \sin(n\theta)\sin(\omega t) = \cos(n\theta - \omega t)$$

- Electrodes separated by:
  – ¼ wavelength in space
  – 90°in phase

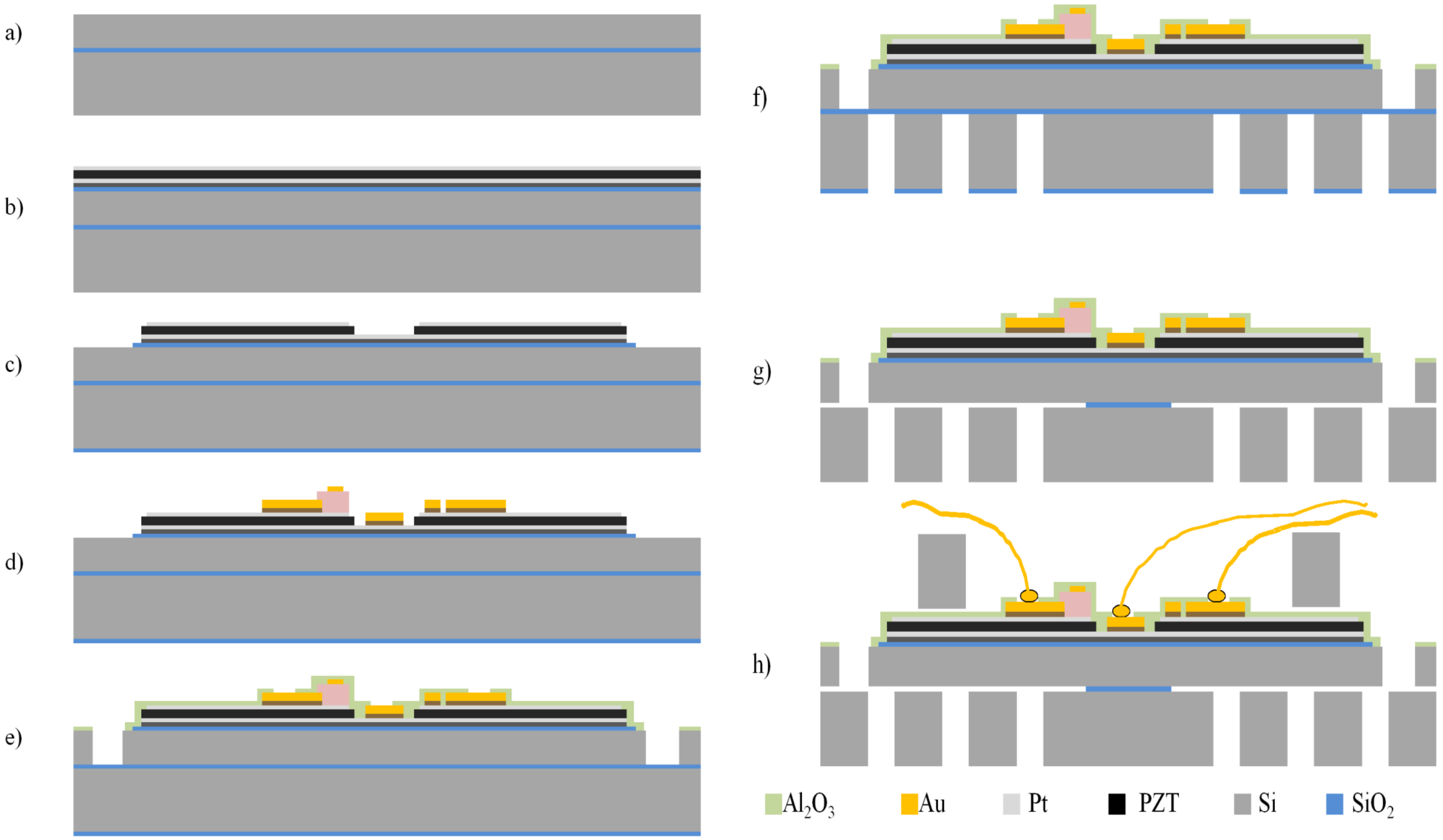


Note: Exaggerated z displacements for visualization



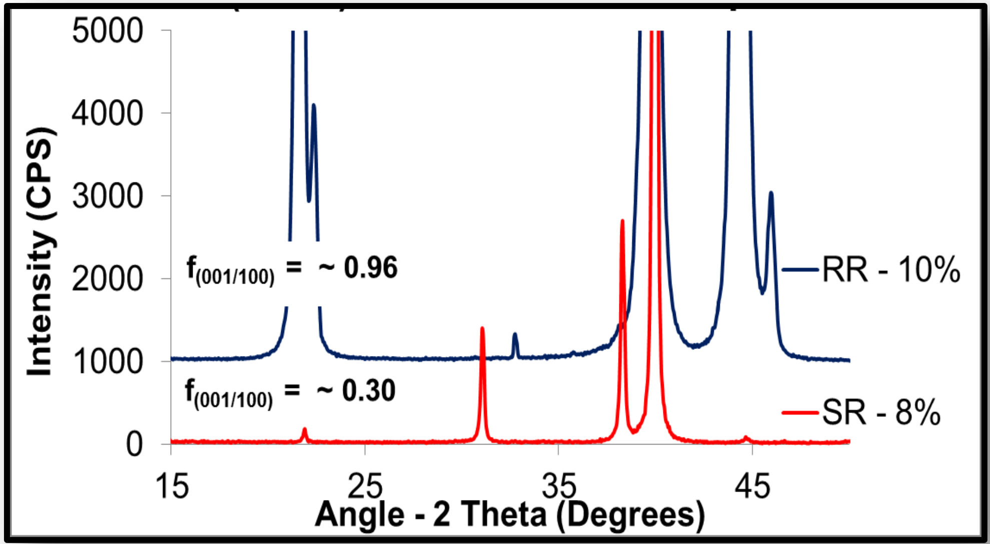


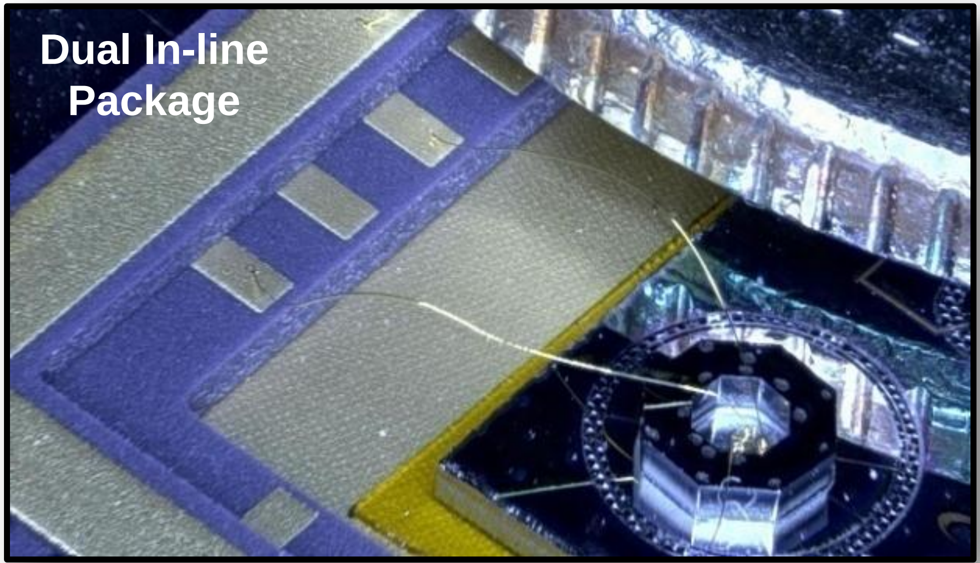
Fabrication Process



Fabrication Specifics

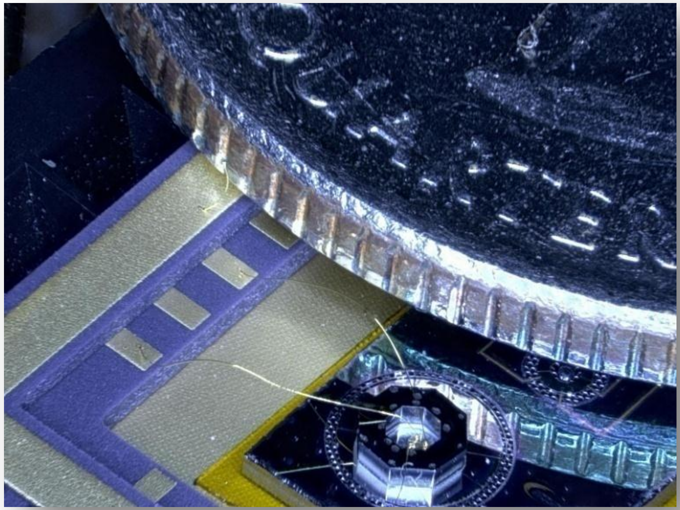
- PZT (52/48) thin films
  - Deposited by chemical solution deposition with 10% Pb excess
  - Pt template (111) with a FWHM of 2 deg
  - (001) PZT with a Lotgering Factor > 0.95
- Pt & PZT Patterning → Ion-mill configured with SIMS endpoint detection
- ALD Al_2O_3 added to provide etch barrier for Vapor HF
- Final Release
  - Backside DRIE of Si
  - Die separation
  - Wirebonding in DIP
  - Vapor HF release of Buried Ox



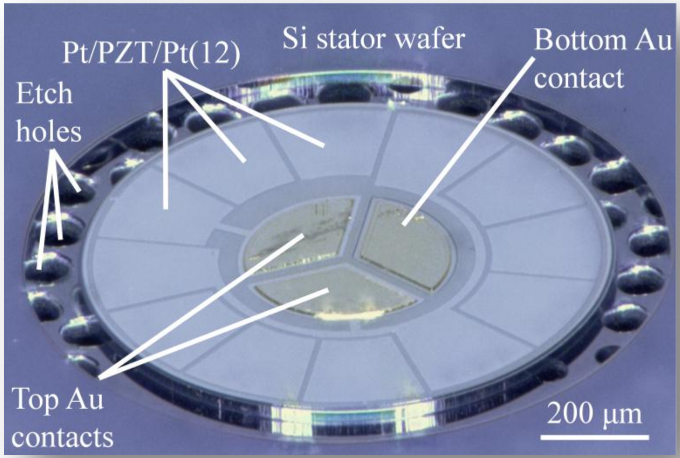


USM

Modeled/Experimental Motor Parameters	
Parameter	**Value**
Voltage input	0-10V
Stator diameter	0.5 - 3 mm
Stator height	30 µm
PZT thickness	1 µm
Eigenfrequency (B13 mode) 3mm	240 kHz
Max output speed	2400 RPM
Maximum output (stall) torque	3.5 N mm
Input power @ 1 Hz	8 mW

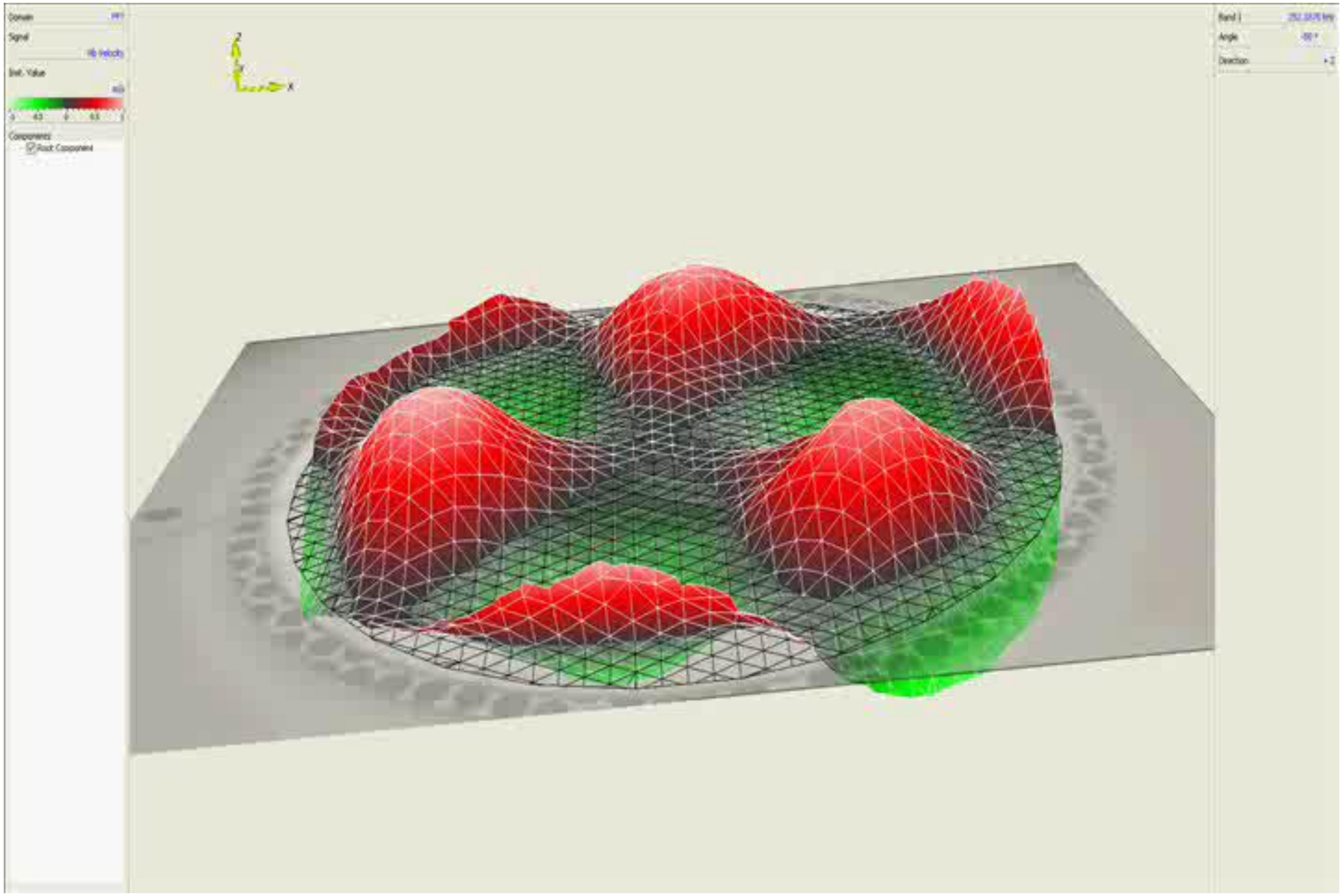


Proof-of-concept motor



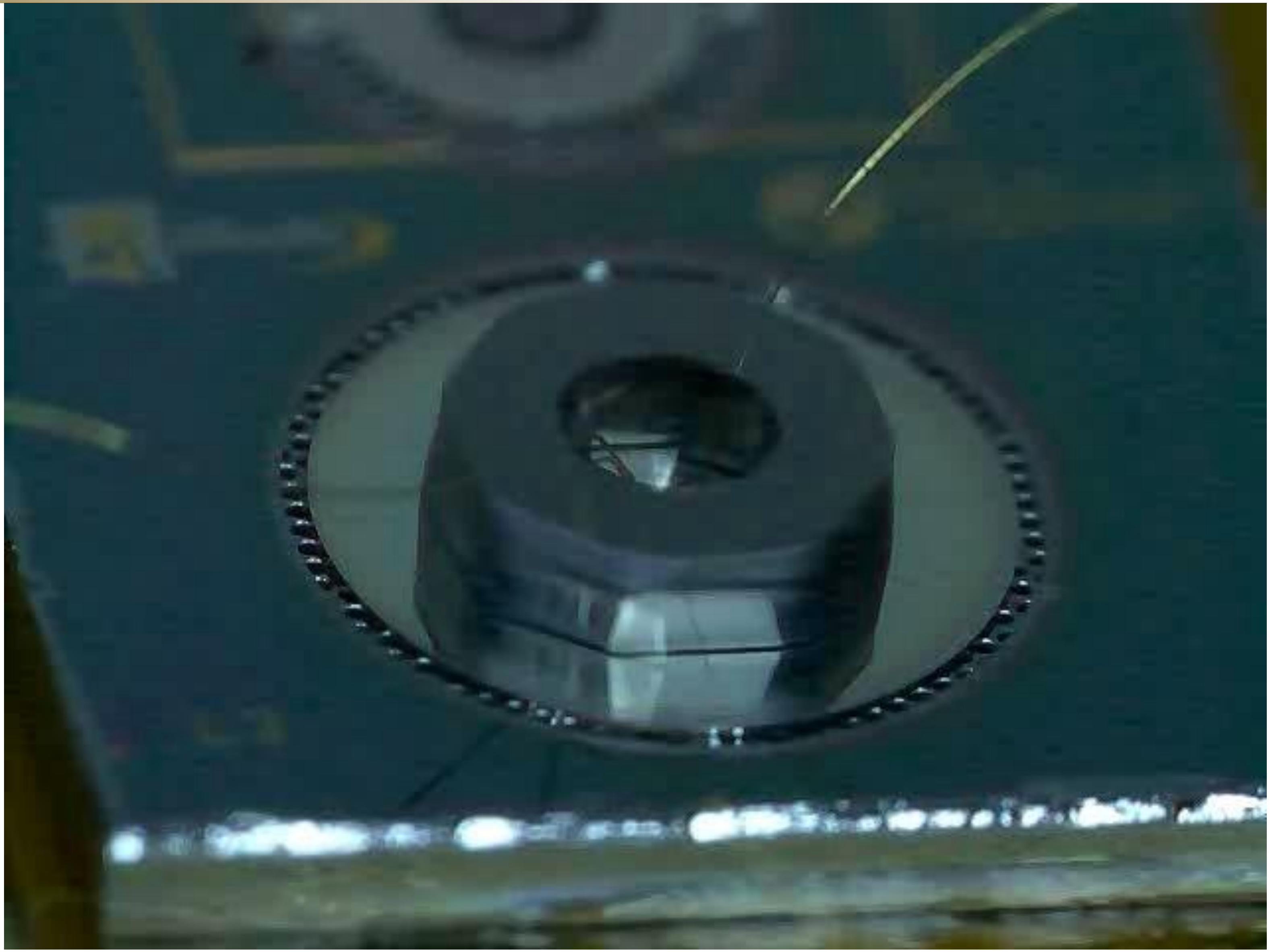
Center fixed stator disc

Laser Doppler Vibrometer

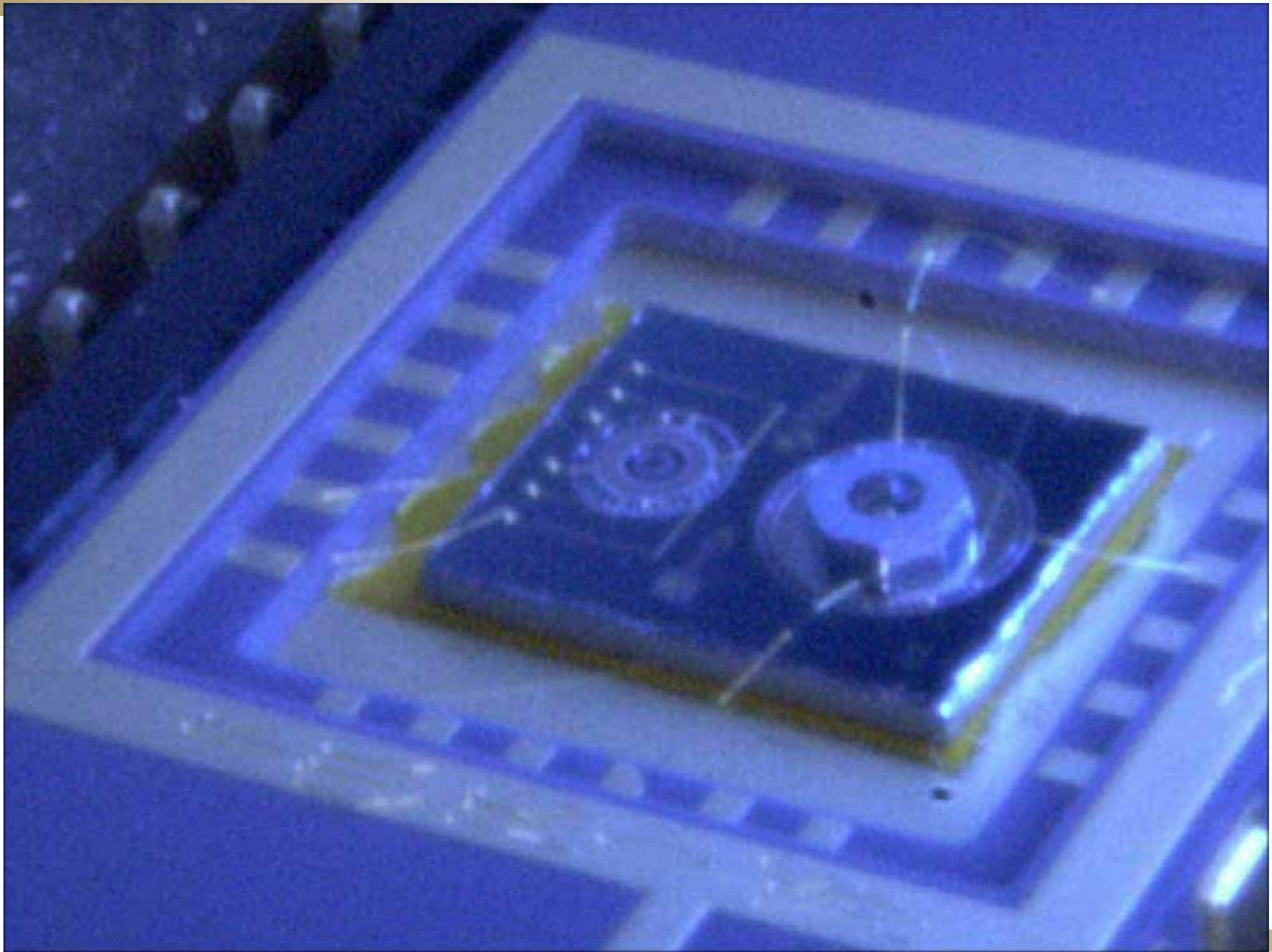


Characterized on a Polytec LDV
Traveling wave peaks travel 80kHz for 3mm stator @ 240kHz resonant excitation

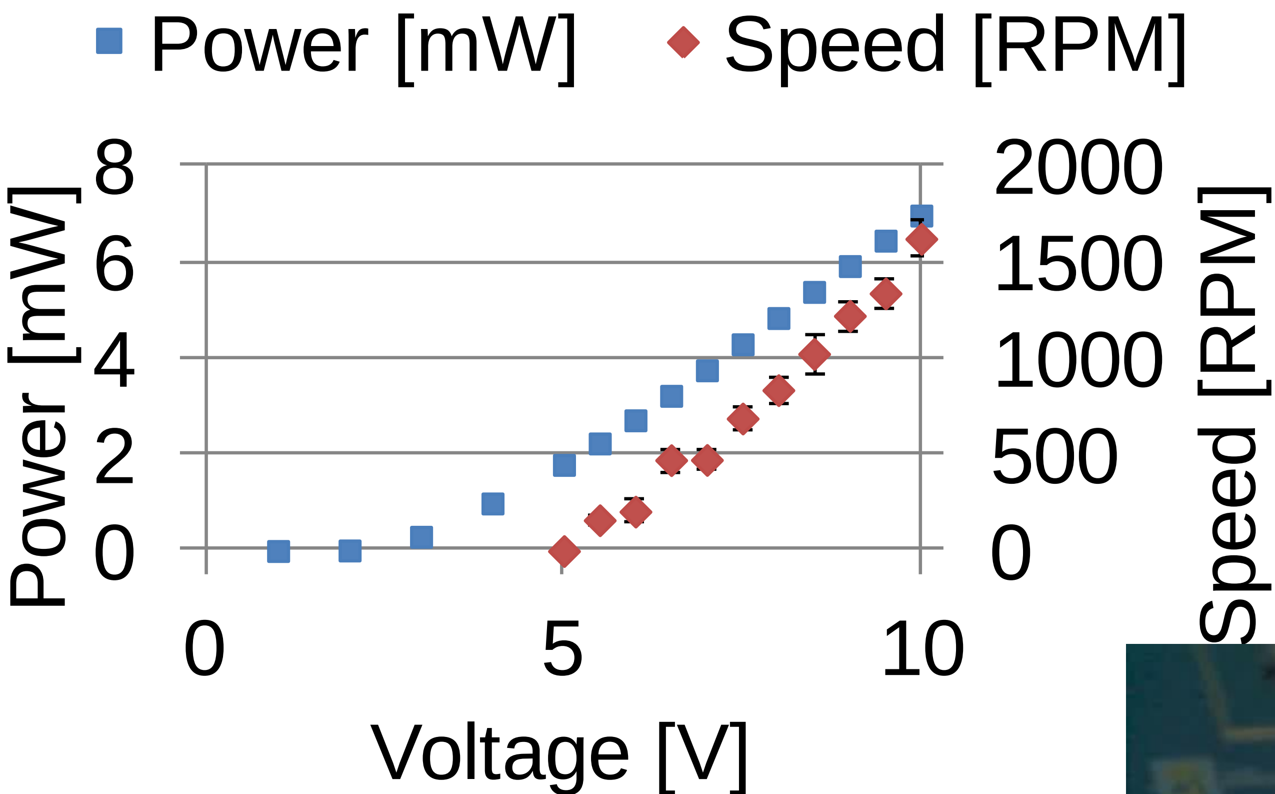
2mm Rotor on 3mm Stator
1000 FPS



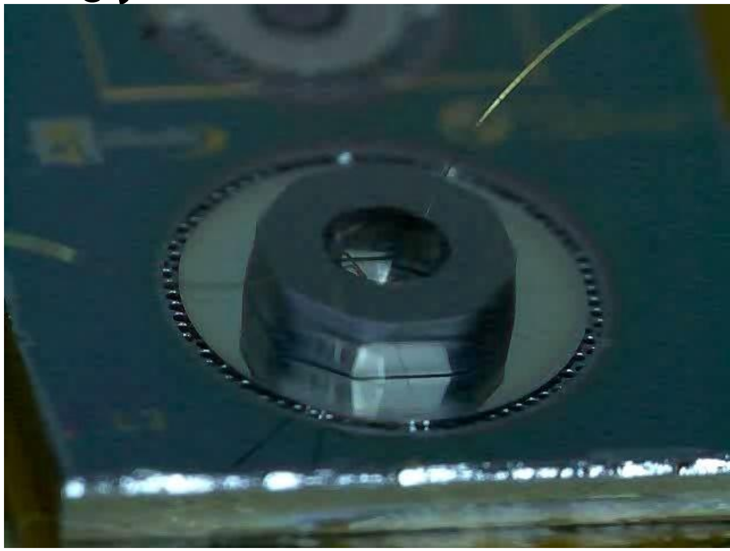
Same Motor in Real-time



Motor Performance



- Rotor motion captured using high speed camera
- 2mm rotor on 3 mm stator
- Speed is linear with voltage
- Bi-directional motion with phase change



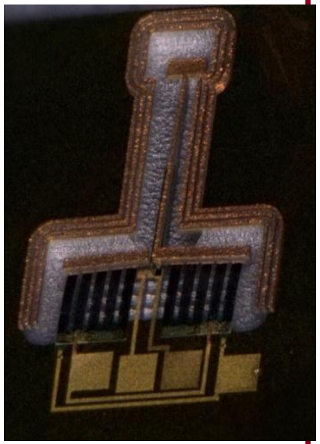
Conclusions & Future Work

PiezoMEMS Haltere

- PiezoMEMS Haltere was designed to detect angular rate.
- Individual, coupled, and arrayed halteres were fabricated in the MEMS cleanroom at ARL-ALC.
- Drive motion demonstrated.
- Initial materials, composite, and dynamic testing is underway on the completed sensors.

Future work:

- Reduce amplifier noise
- Quantify rate sensitivity on rotating platform.
- Iterate design for greater rate sensitivity.



Approved for Public Release

Traveling Wave Motor

•Proof-of-concept motor demonstrated and characterized

•Traveling wave stator motion measured and characterized

•Motor performance model developed.

Future Work:

•Stator Tooth Integration

- Electroplating
- Aerosol jet deposition

- Wafer scale rotor integration and clamping mechanism
- Frictional material characterization
- FPGA control or ASIC